



Faculty of Manufacturing Engineering

**DEVELOPMENT OF FINGER TYPE TACTILE SENSOR WITH
SURFACE ROUGHNESS ANALYSIS**

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Master of Science in Manufacturing Engineering

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**DEVELOPMENT OF FINGER TYPE TACTILE SENSOR WITH SURFACE
ROUGHNESS ANALYSIS**

SHAFIYAH BINTI ABD RASHID

**A thesis submitted
in the fulfilment of the requirements for the degree of Master of Science
in Manufacturing Engineering**

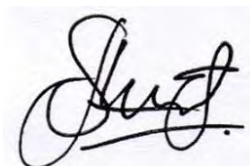
Faculty of Manufacturing Engineering

UNIVERSITI TEKNIKAL MALAYSIA MELAKA

2018

DECLARATION

I declare that this thesis entitled “Development of Finger Type Tactile Sensor with Surface Roughness Analysis” is the result of my own research except as cited in the references. The thesis has not been accepted for any degree and is not concurrently submitted in candidature of any other degree.



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APPROVAL

I hereby declare that I have read this thesis and in my opinion this thesis is sufficient in terms of scope and quality for the award of Master of Science in Manufacturing Engineering.

Signature :

Supervisor Name : DR. FAIRUL AZNI BIN JAFAR

Date :

DEDICATION

Gratitude to God Almighty ALLAH S.W.T and His Messenger MUHAMMAD S.A.W that

has given me the perfection for

solving this thesis.

Special thanks to my father and mother,

Abd Rashid B. Yusof and AsmaliaBtJaafar,

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involved directly or indirectly,

a lot of help in preparing this thesis.

Only ALLAH S.W.T is able to respond to the

dignityof life helped me deal with this.

ABSTRACT

This research is focused on the development of finger type tactile sensor with surface roughness analysis. Among various human sensations like hearing, sight, taste and smell, touch is a critical co-existing sensation required to interact with surrounding environment. Therefore, it is believed that a good understanding between the touch and surface roughness have potential benefits to the performance of the finger type tactile sensor robot. Even though there is a lot of tactile sensor's type used in robotic application but there is much less on work has been done on load cell. As far as it is concerned, tactile sensor, vision and audio system is very expensive. Therefore, something cheaper which is load cell is used as a replace for other expensive tactile sensor, in order to modelling and develop a finger type tactile sensor. So, a knowledge study regarding on tactile sensor, touch and grasping are investigated in order to proceed the research. Next, the finger type tactile sensor is designed and developed in SolidWorks software for visual- aided all the view of prototype. To achieve the sensory performance and function of the human fingertips, the design of the fingertips sensor mimics the human fingertips in many aspects, including its size and shape. As objects slide across the structure of surface roughness of the finger type tactile sensor, it generates force that measure in ADC (Volt) that are detected by a loadcells inside the holder. By using Graphical User Interface (GUI), data logging for every extracted graph of each experiment is performed. The developed finger type tactile sensor needs to be tested in order to identify the performance capability of the sensor according to the designed function. A set of 3D printed objects with different values of roughness has been prepared as the sample for this test. Then, for performance validation, Experiment 1: Calibration (Mitutoyo Precision Reference Specimen) has been conducted between using manual robot (Z-arm) and auto robot (Comau Robot). Comau Robot has been chosen as the most suitable robot for the rest of the experiments, then the work is extended to Experiment 2 (Test using Needle File) and Experiment 3 (Test using Tile). The experiment results show that the functionality of the finger type tactile sensor has been successfully validated and proven acceptable for all set of experiment.

ABSTRAK

Kajian ini memberitumpuan kepada perkembangan Peranti Sentuhan Bentuk jari dengan analisis kekasaran permukaan. Manusia mempunyai pelbagai deria seperti pendengaran, penglihatan, rasa dan bau. Akan tetapi, deria sentuhan adalah sangat penting untuk berinteraksi dengan kekasaran permukaan sesuatu objek. Oleh itu, dipercayai bahawa pemahaman yang baik tentang deria sentuhan dan kekasaran permukaan mempunyai potensi yang tinggi dalam meningkatkan prestasi Peranti Sentuhan Bentuk jari. Walaupun terdapat banyak jenis peranti sentuhan yang digunakan dalam aplikasi robotik tetapi masih kurang yang menggunakan aplikasi sel beban. Setakat ini, peranti sentuhan, vision dan sistem audio sangat mahal dan sebagai pelajar, saya tidak mempunyai banyak wang untuk membeli peranti tersebut. Oleh itu, berurusan dengan keadaan ini, membuat saya mencari sesuatu yang lebih murah iaitu sel beban sebagai pengganti peranti sentuhan mahal yang lain, untuk memodelkan dan membangunkan peranti jenis sentuhan jari. Oleh itu, satu kajian pengetahuan mengenai peranti sentuhan, sentuhan dan konsep genggam jari robot diasaskan untuk meneruskan penyelidikan. Selanjutnya, Peranti Sentuhan Bentuk jari direka dan dibangunkan dalam perisian Solid Work untuk melihat semua prototaip visual. Untuk mencapai prestasi dan fungsi deria sentuh yang sama seperti manusia, reka bentuk peranti jari adalah meniru jari manusia dalam banyak aspek, termasuk saiz dan bentuknya. Apabila objek melintasi Peranti Sentuhan Bentuk jari, kuasa dijanakan dan diukur dalam ADC yang dikesan oleh sel beban di dalamnya. Dengan menggunakan Perisian GUI, eksperimen dijalankan untuk mendapatkan data bagi setiap graf yang diekstrak. Peranti Sentuhan Bentuk jari seterusnya diuji untuk mengenalpasti prestasi keupayaan yang mengikut fungsi yang dirancang. Satu set bahan eksperimen bercetak 3D dengan pelbagai nilai kekasaran telah disediakan sebagai sampel untuk ujian ini. Kemudian, untuk pengesahan prestasi, Eksperimen 1: Penentuan (Specimen Rujukan Ketepatan Mitutoyo) telah dijalankan menggunakan robot manual (Z-arm) dan robot automatik (Comau Robot). Selepas Comau Robot dipilih sebagai robot yang paling sesuai untuk seluruh eksperimen, maka eksperimen ini akan diteruskan ke Eksperimen 2 (Ujian menggunakan Kikir Jarum) dan Eksperimen 3 (Ujian menggunakan Jubin). Mengikut hasil Eksperimen 1 dan seterusnya, ini mengesahkan bahawa bacaan Peranti Sentuhan Bentuk jari adalah berfungsi seperti yang dikehendaki dan boleh diterima untuk semua set eksperimen.

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TABLE OF CONTENTS

	PAGE
DECLARATION	
APPROVAL	
DEDICATION	
ABSTRACT	i
ABSTRAK	ii
ACKNOWLEDGEMENTS	iii
TABLE OF CONTENTS	iv
LIST OF TABLES	vi
LIST OF FIGURES	vii
LIST OF APPENDICES	xvi
LIST OF SYMBOLS	xix
LIST OF ABBREVIATIONS	xx
LIST OF PUBLICATIONS	xxi

CHAPTER

1. INTRODUCTION	1
1.1 Background	1
1.2 Motivation	3
1.3 Problem Statement	6
1.4 Research Question	7
1.5 Objectives	8
1.6 Scope	8
1.7 Organization	9
2. LITERATURE REVIEW	11
2.1 Haptic Sensing Technology	11
2.1.1 Haptic Sensing Technology in Robotic Application	14
2.1.2 Tactile Sensor	17
2.2 Robot Finger Sensor	23
2.3 Application of Finger Sensor	27
2.3.1 Sense of Touch	27
2.3.2 Grasping	29
2.3.3 Measuring Roughness	31
2.4 Summary	38
3. METHODOLOGY	39
3.1 Overall Research Work Flowchart	39
3.2 Phase I: Modelling the Finger Type Tactile Sensor	41
3.2.1 Design of Prototype	41
3.2.2 Concept of the Sensor	43

3.3	Phase II: Development of Finger Type Tactile Sensor	46
3.3.1	Hardware	48
3.3.2	Software	51
3.3.3	Performance Test	52
3.4	Phase III: Performance Validation	54
3.4.1	Experimental Setup	55
3.4.1.1	Experiment 1: Mitutoyo Precision Reference Specimen Test	55
3.4.1.2	Experiment 2: Test using Needle File	56
3.4.1.3	Experiment 3: Test using Tile	57
3.4.2	Experimental Procedure	59
3.4.3	Experimental Platform	60
3.4.4	Data Analysis	66
3.4.5	Verification on performance validation of finger sensor	67
3.5	Summary	68
4.	RESULT AND DISCUSSION	69
4.1	Performance Test	69
4.2	Experiment 1: Mitutoyo Precision Reference Specimen Test	80
4.3	Experiment 2: Tile Experiment	98
4.4	Experiment 3: Needle File Experiment	110
4.5	Summary	123
5.	CONCLUSION	124
5.1	Conclusion	124
5.2	Research Contribution	125
5.3	Future Works	127
	REFERENCES	128
	APPENDICES	141

LIST OF TABLES

TABLE	TITLE	PAGE
4.1	Table of Print File's roughness (using Z-arm with polyjet cover)	73
4.2	Table of Print File's roughness (using Z-arm without polyjet cover)	78
4.3	Table of roughness of Mitutoyo Precision Specimen (Z-arm)	87
4.4	Table of roughness Mitutoyo Precision Reference Specimen (Comau Robot/ Auto)	95
4.5	Table of roughness of Tile	108
4.6	Table of roughness of N File set 1	122

LIST OF FIGURES

FIGURE	TITLE	PAGE
1.1	Mechanosensory information transmitted from the fingertip to the brain (Zhengkun, 2017)	5
2.1	Pancakes process(MistaPrime Minista, 2014)	15
2.2	Theconcept for picking robot (Kitamura, 2005)	16
2.3	Force or Torque Sensor	18
2.4	Dynamic sensor	19
2.5	Thermal Sensor	19
2.6	Sensor structure (Drimus, 2012)	20
2.7	Sketch of the working principle (Maria, 2012)	21
2.8	Variation of capacitance due to applied force (Yousef, 2011)	22
2.9	Optical three-axis tactile sensor mounted on two robot fingers (Ohka, 2012)	25
2.10	Three-axis tactile sensor system (Abdullah, 2012)	26
2.11	Basic systemconfiguration (Sivaraj, 2012)	27
2.12	Proposed soft robotic gripper with variable stiffness (Haibin, 2018)	30
2.13	Robotic arm and hand system explores a shape in simulation and	30

	grasps compliantly an object on a real platform (Sommer, 2016)	
2.14	Portable machine roughness	31
2.15	Bio-inspired tactile sensor with a hard cap (left) and its inner structure (right) (Qin, 2018)	32
2.16	Structure of the finger-shaped tactile sensor (Hu, 2014)	34
2.17	Biotacsensors (Fishel, 2012)	35
2.18	Structures of (a) the designed artificial fingertip, (b) a developed artificial fingertip, (c) structure of human fingertip, and (d) artificial vs. human fingertip. The structures of both human and artificial fingertips contain two layers with different hardness, and a bone (Zhengkun, 2017)	36
2.19	Fabricated sensor die mounted on DIP chip carrier (Muhammad, 2011)	38
3.1	Research work flow chart	40
3.2	SolidWorks drawing of fingertips sensor	41
3.3	Orthographic view of fingertips sensor	42
3.4	Development of Fingertips Sensor	43
3.5	Phase II: Development of fingertips sensor	46
3.6	Schematic design fingertips sensor	48
3.7	Real prototype of fingertips sensor; (a) Electronic part of fingertips sensor, (b) Small compartment, (c) Fingertips sensor with polyjet cover	50
3.8	Finger type tactile sensor GUI	52
3.9	Printed samples	53

3.10	Phase III: Overall Method Performance Validation	54
3.11	Mitutoyo precision reference specimen	56
3.12	Sample of needle file	56
3.13	Real experiment layout for file using Comau Robot	57
3.14	Sample of tile	58
3.15	Real experiment layout for tile using Comau Robot	58
3.16	Condition of Experiment 2 when the finger sensor touch specimen	60
3.17	Z-arm experimental layout	60
3.18	Comau experimental layout	61
3.19	SolidWorks drawing of robot arm with fingertips sensor	62
3.20	Orthographic view of SolidWorks drawing for robot arm with fingertips sensor	62
3.21	Orthographic view of SolidWorks drawing for robot arm with fingertips sensor	64
3.22	Orthographic and Isometric of SolidWorks drawing for full robot with fingertips sensor	65
3.23	SolidWorks drawing of full robot with fingertips sensor	66
4.1	Printed file 1 (Z-arm with polyjet cover)	69
4.2	Printed file 2 (Z-arm with polyjet cover)	70
4.3	Printed file 3 (Z-arm with polyjet cover)	70
4.4	Printed file 4 (Z-arm with polyjet cover)	70
4.5	Printed file 5 (Z-arm with polyjet cover)	71
4.6	Printed file 6 (Z-arm with polyjet cover)	71
4.7	Printed file 7 (Z-arm with polyjet cover)	71

4.8	Printed file 8 (Z-arm with polyjet cover)	72
4.9	Printed file 9 (Z-arm with polyjet cover)	72
4.10	Printed file 10 (Z-arm with polyjet cover)	72
4.11	Printed file 1 (Z-arm without polyjet cover)	75
4.12	Printed file 2 (Z-arm without polyjet cover)	75
4.13	Printed file 3 (Z-arm without polyjet cover)	75
4.14	Printed file 4 (Z-arm without polyjet cover)	76
4.15	Printed file 5 (Z-arm without polyjet cover)	76
4.16	Printed file 6 (Z-arm without polyjet cover)	76
4.17	Printed file 7 (Z-arm without polyjet cover)	77
4.18	Printed file 8 (Z-arm without polyjet cover)	77
4.19	Printed file 9 (Z-arm without polyjet cover)	77
4.20	Printed file 10 (Z-arm without polyjet cover)	78
4.21	Final prototype of finger sensor	79
4.22	Series for type of sensor	80
4.23	Graph of roughness for sample 2.94 a (upwards) (Z-arm)	80
4.24	Graph of roughness for sample 2.94 b (upwards) (Z-arm)	80
4.25	Graph of roughness for sample 2.94 c (upwards) (Z-arm)	81
4.26	Graph of roughness for sample 2.94 d (upwards) (Z-arm)	81
4.27	Graph of roughness for sample 2.94 e (upwards) (Z-arm)	81
4.28	Graph of roughness for sample 2.94 a (downwards) (Z-arm)	82
4.29	Graph of roughness for sample 2.94 b (downwards) (Z-arm)	82
4.30	Graph of roughness for sample 2.94 c (downwards) (Z-arm)	82
4.31	Graph of roughness for sample 2.94 d (downwards) (Z-arm)	83

4.32	Graph of roughness for sample 2.94 e (downwards) (Z-arm)	83
4.33	Graph of roughness for sample 3.05 a (upwards) (Z-arm)	83
4.34	Graph of roughness for sample 3.05 b (upwards) (Z-arm)	84
4.35	Graph of roughness for sample 3.05 c (upwards) (Z-arm)	84
4.36	Graph of roughness for sample 3.05 d (upwards) (Z-arm)	84
4.37	Graph of roughness for sample 3.05 e (upwards) (Z-arm)	85
4.38	Graph of roughness for sample 3.05 a (downwards) (Z-arm)	85
4.39	Graph of roughness for sample 3.05 b (downwards) (Z-arm)	85
4.40	Graph of roughness for sample 3.05 c (downwards) (Z-arm)	86
4.41	Graph of roughness for sample 3.05 d (downwards) (Z-arm)	86
4.42	Graph of roughness for sample 3.05 e (downwards) (Z-arm)	86
4.43	Graph for Overall Mitutoyo Reference Specimen (Z-arm) (2.94 μ m)	87
4.44	Graph for Overall Mitutoyo Reference Specimen (Z-arm) (3.05 μ m)	87
4.45	Graph for Σ Average for Mitutoyo Reference Specimen (Z-arm)	88
4.46	Graph of roughness for sample 2.94 a (upwards) (Comau)	88
4.47	Graph of roughness for sample 2.94 b (upwards) (Comau)	88
4.48	Graph of roughness for sample 2.94 c (upwards) (Comau)	89
4.49	Graph of roughness for sample 2.94 d (upwards) (Comau)	89
4.50	Graph of roughness for sample 2.94 e (upwards) (Comau)	89
4.51	Graph of roughness for sample 2.94 a (downwards) (Comau)	90
4.52	Graph of roughness for sample 2.94 b (downwards) (Comau)	90
4.53	Graph of roughness for sample 2.94 c (downwards) (Comau)	90

4.54	Graph of roughness for sample 2.94 d (downwards) (Comau)	91
4.55	Graph of roughness for sample 2.94 e (downwards) (Comau)	91
4.56	Graph of roughness for sample 3.05 a (upwards) (Comau)	91
4.57	Graph of roughness for sample 3.05 b (upwards) (Comau)	92
4.58	Graph of roughness for sample 3.05 c (upwards) (Comau)	92
4.59	Graph of roughness for sample 3.05 d (upwards) (Comau)	92
4.60	Graph of roughness for sample 3.05 e (upwards) (Comau)	93
4.61	Graph of roughness for sample 3.05 a (downwards) (Comau)	93
4.62	Graph of roughness for sample 3.05 b (downwards) (Comau)	93
4.63	Graph of roughness for sample 3.05 c (downwards) (Comau)	94
4.64	Graph of roughness for sample 3.05 d (downwards) (Comau)	94
4.65	Graph of roughness for sample 3.05 e (downwards) (Comau)	94
4.66	Graph for Overall Mitutoyo Reference Specimen (Comau) (2.94 μ m)	95
4.67	Graph for Overall Mitutoyo Reference Specimen (Comau) (3.05 μ m)	95
4.68	Graph for Σ Average for Mitutoyo Reference Specimen (Comau Robot/ Auto)	96
4.69	Graph of Tile sample 1a	98
4.70	Graph of Tile sample 1b	98
4.71	Graph of Tile sample 1c	99
4.72	Graph of Tile sample 2a	99
4.73	Graph of Tile sample 2b	99
4.74	Graph of Tile sample 2c	100
4.75	Graph of Tile sample 3a	100

4.76	Graph of Tile sample 3b	100
4.77	Graph of Tile sample 3c	101
4.78	Graph of Tile sample 4a	101
4.79	Graph of Tile sample 4b	101
4.80	Graph of Tile sample 4c	102
4.81	Graph of Tile sample 5a	102
4.82	Graph of Tile sample 5b	102
4.83	Graph of Tile sample 5c	103
4.84	Graph of Tile sample 6a	103
4.85	Graph of Tile sample 6b	103
4.86	Graph of Tile sample 6c	104
4.87	Graph of Tile sample 7a	104
4.88	Graph of Tile sample 7b	104
4.89	Graph of Tile sample 7c	105
4.90	Graph of Tile sample 8a	105
4.91	Graph of Tile sample 8b	105
4.92	Graph of Tile sample 8c	106
4.93	Graph of Tile sample 9a	106
4.94	Graph of Tile sample 9b	106
4.95	Graph of Tile sample 9c	107
4.96	Graph of Tile sample 10a	107
4.97	Graph of Tile sample 10b	107
4.98	Graph of Tile sample 10c	108
4.99	Graph of experiment Tile	109

4.100	Graph of N File set1 1a	110
4.101	Graph of N File set1 1b	110
4.102	Graph of N File set1 1c	110
4.103	Graph of N File set1 2a	111
4.104	Graph of N File set1 2b	111
4.105	Graph of N File set1 2c	111
4.106	Graph of N File set1 3a	112
4.107	Graph of N File set1 3b	112
4.108	Graph of N File set1 3c	112
4.109	Graph of N File set1 4a	113
4.110	Graph of N File set1 4b	113
4.111	Graph of N File set1 4c	113
4.112	Graph of N File set1 5a	114
4.113	Graph of N File set1 5b	114
4.114	Graph of N File set1 5c	114
4.115	Graph of N File set1 6a	115
4.116	Graph of N File set1 6b	115
4.117	Graph of N File set1 6c	115
4.118	Graph of N File set1 7a	116
4.119	Graph of N File set1 7b	116
4.120	Graph of N File set1 7c	116
4.121	Graph of N File set1 8a	117
4.122	Graph of N File set1 8b	117
4.123	Graph of N File set1 8c	117

4.124	Graph of N File set1 9a	118
4.125	Graph of N File set1 9b	118
4.126	Graph of N File set1 9c	118
4.127	Graph of N File set1 10a	119
4.128	Graph of N File set1 10b	119
4.129	Graph of N File set1 10c	119
4.130	Graph of N File set1 11a	120
4.131	Graph of N File set1 11b	120
4.132	Graph of N File set1 11c	120
4.133	Graph of N File set1 12a	121
4.134	Graph of N File set1 12b	121
4.135	Graph of N File set1 12c	121
4.136	Graph of experiment N File set 1	122

LIST OF APPENDICES

APPENDIX	TITLE	PAGE
A1	Graph of N File set2 1	141
A2	Graph of N File set2 2	142
A3	Graph of N File set2 3	143
A4	Graph of N File set2 4	144
A5	Graph of N File set2 5	145
A6	Graph of N File set2 6	146
A7	Graph of N File set3 1	147
A8	Graph of N File set3 2	148
A9	Graph of N File set3 3	149
A10	Graph of N File set3 4	150
A11	Graph of N File set3 5	151
A12	Graph of N File set3 6	152
A13	Graph of N File set3 7	153
A14	Graph of N File set3 8	154
A15	Graph of N File set3 9	155
A16	Graph of N File set3 10	156
A17	Graph of N File set3 11	157

A18	Graph of N File set4 1	158
A19	Graph of N File set4 2	159
A20	Graph of N File set4 3	160
A21	Graph of N File set4 4	161
A22	Graph of N File set4 5	162
A23	Graph of N File set4 6	163
A24	Graph of N File set5 1	164
A25	Graph of N File set5 2	165
A26	Graph of N File set5 3	166
A27	Graph of N File set5 4	167
A28	Graph of N File set5 5	168
A29	Graph of N File set5 6	169
A30	Graph of N File set5 7	170
A31	Graph of N File set5 8	171
A32	Graph of N File set5 9	172
A33	Graph of N File set5 10	173
A34	Graph of N File set5 11	174
A35	Graph of N File set6 1	175
A36	Graph of N File set6 2	176
A37	Graph of N File set6 3	177
A38	Graph of N File set6 4	178
A39	Graph of N File set6 5	179
A40	Graph of N File set6 6	180
A41	Graph of N File set6 7	181

A42	Graph of N File set6 8	182
A43	Graph of N File set6 9	183
A44	Graph of N File set6 10	184
B1	Table and Graph of roughness of N File set 2	185
B2	Table and Graph of roughness of N File set 3	186
B3	Table and Graph of roughness of N File set 4	187
B4	Table and Graph of roughness of N File set 5	188
B5	Table and Graph of roughness of N File set 6	189

LIST OF SYMBOLS

μm	-	Micrometer
$^{\circ}\text{C}$	-	Temperature (Celcius)
E	-	Electrode impedances
C	-	Manufacturer's Industrial Group
eC	-	Capasitor
D	-	Reverse Polarity
R	-	Resistor
OSC	-	Oscillator or clocking
μm	-	Micrometer
$^{\circ}\text{C}$	-	Temperature (Celcius)